Abstract

A method for controlling the speed of a vehicle (1) ~~is proposed~~, where, in the vehicle (1) to be controlled, the yaw rate or rotation rate is measured, in particular to determine the curvature (k) of the vehicle's own travel trajectory, and where, using a proximity sensor or position sensor (6), at least one vehicle (5,8) traveling ahead or at least some other object within a sensor's sensing range (7) is detected, particularly with regard to an offset from the travel course of the vehicle to be controlled. By delaying the travel-course offset (yc) of a vehicle (5) driving ahead, determined in preset measuring cycles, by a predefined time span (t_{hist}), and by using the then instantaneous curvature (k) of the travel trajectory, a historical travel-course offset (yc_{hist}) is ascertained, one is able to simply and rapidly predict the travel course of the vehicle (1) to be controlled.

~~(Figure 1)~~